

1/16

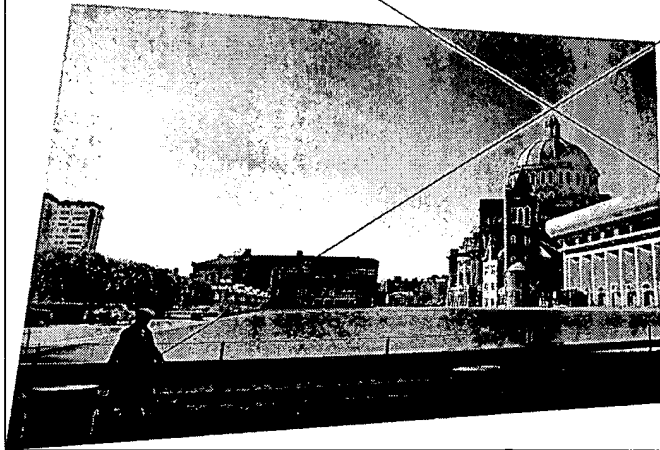
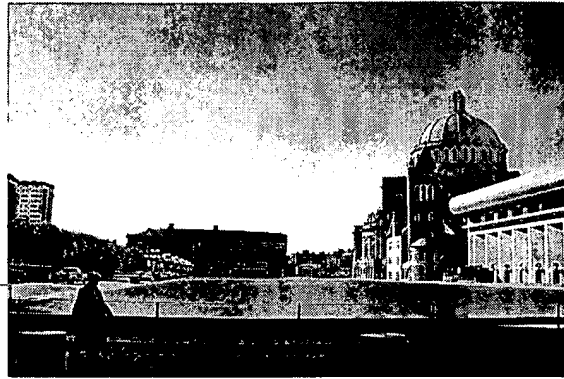


Fig. 1

2/16

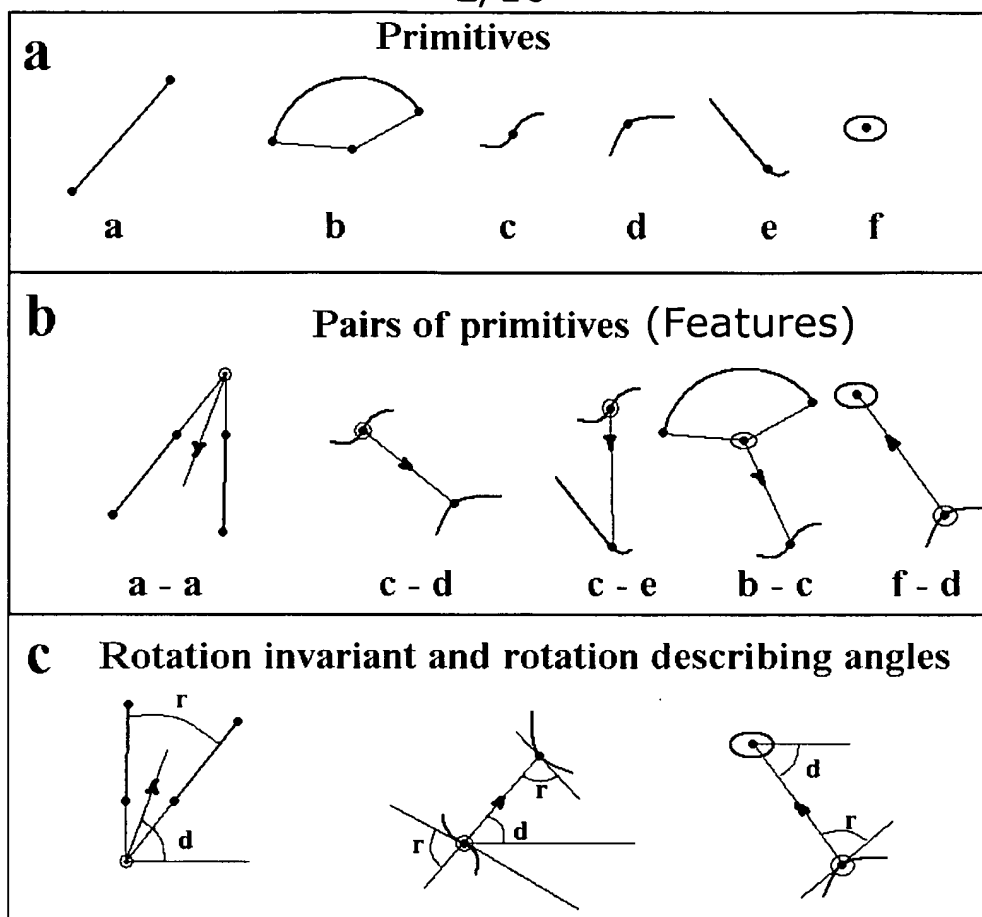


Fig. 2

3/16

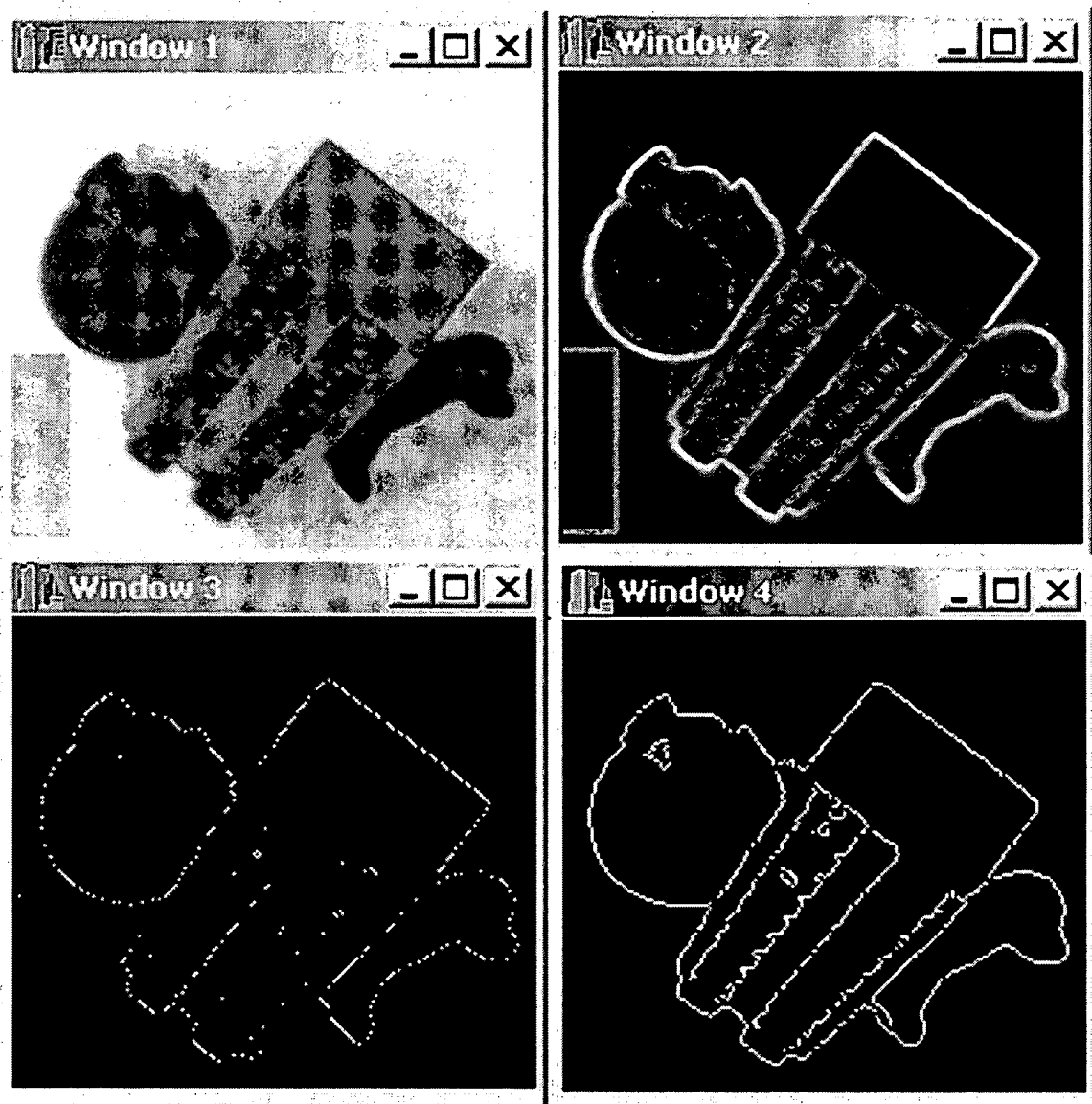


Fig. 3

4/16

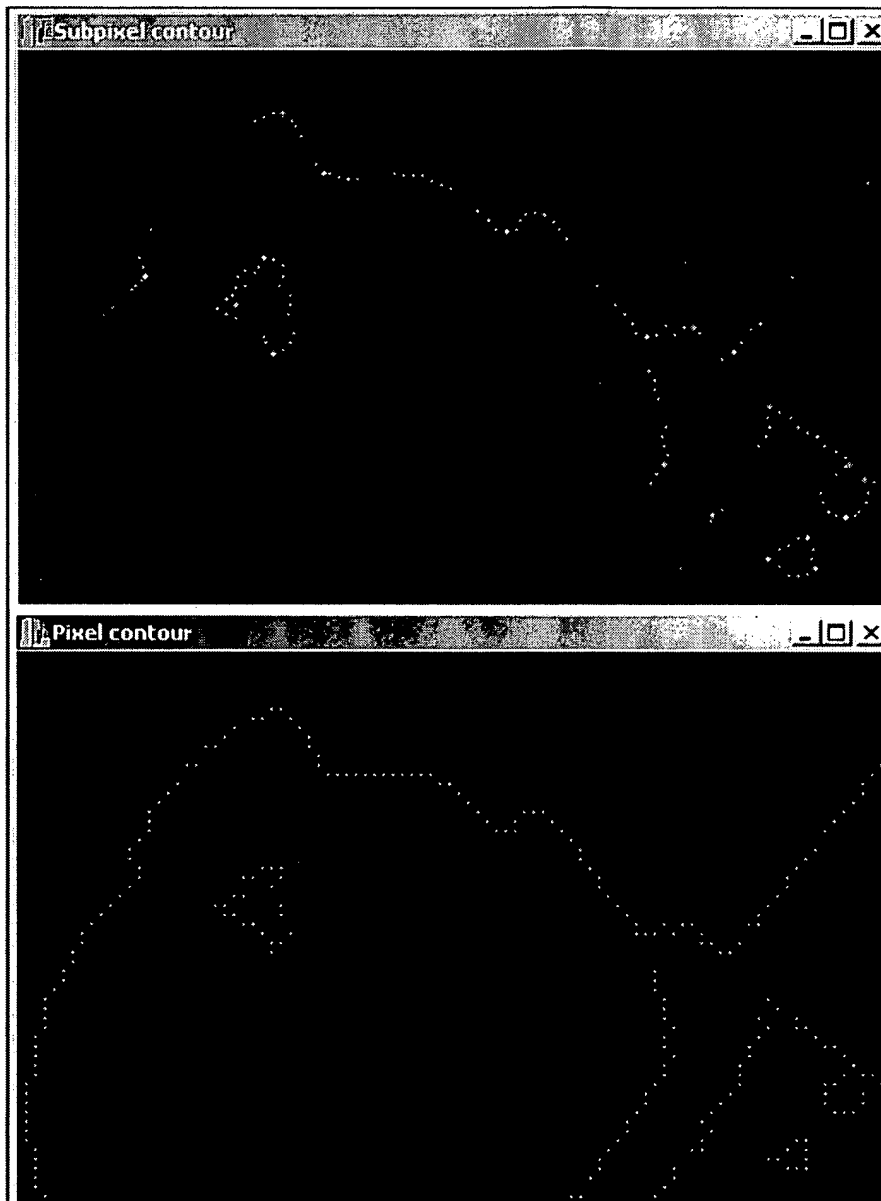


Fig. 4

5/16

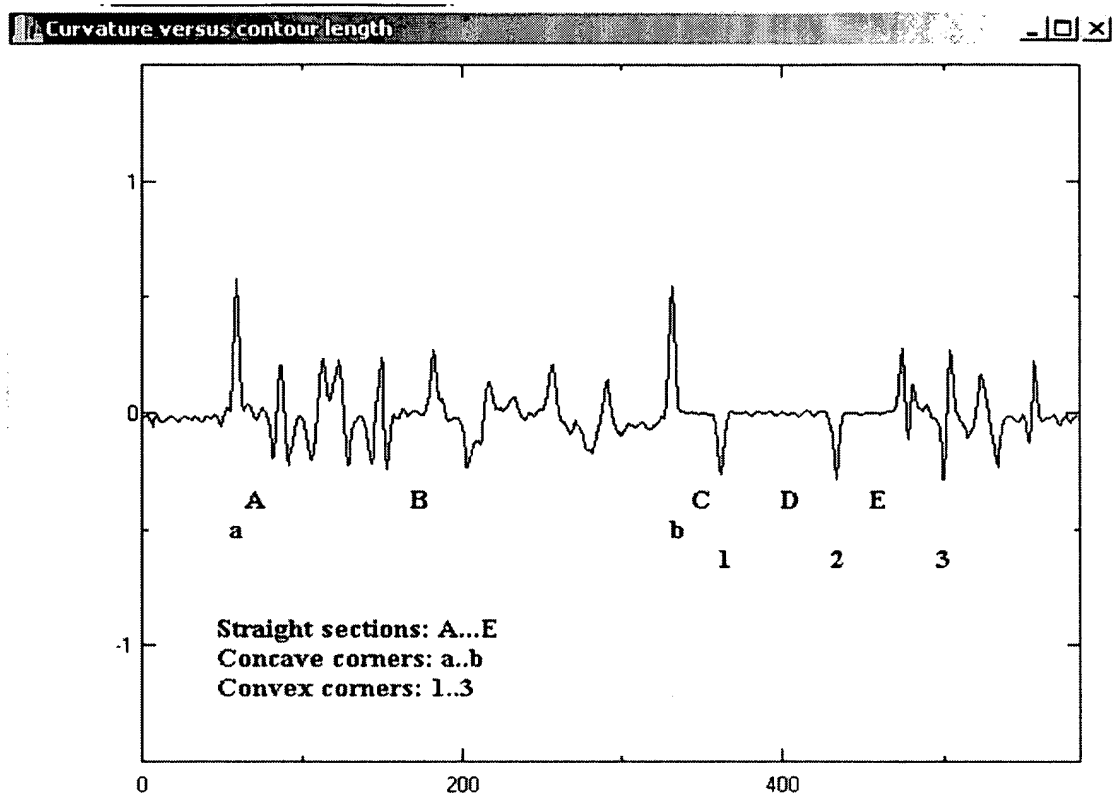


Fig. 5

6/16

Fig. 6

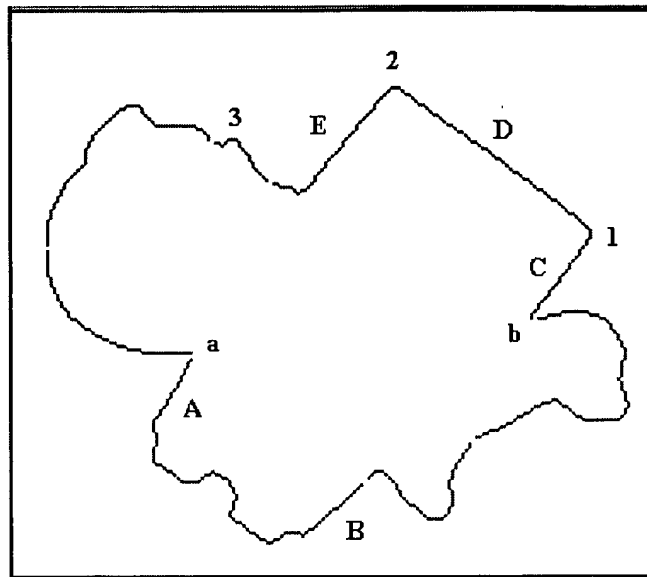
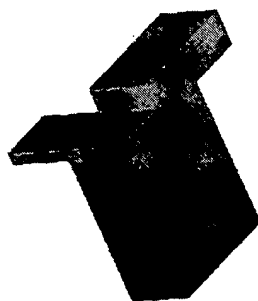


Fig. 7



7/16

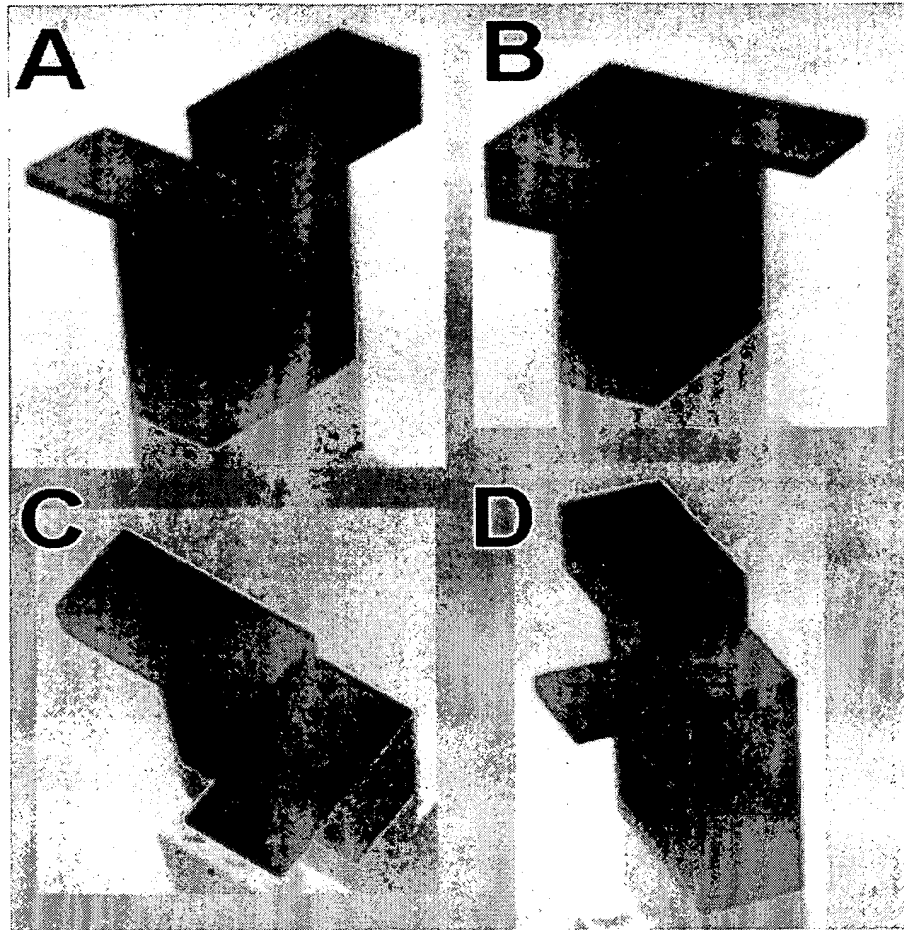


Fig. 8

8/16

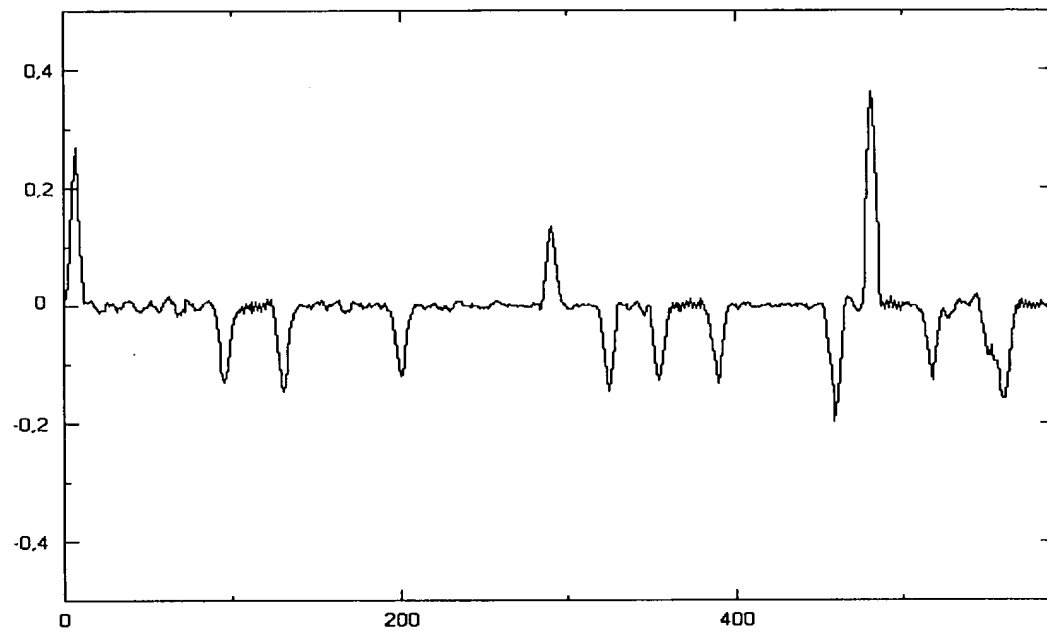


Fig. 9

9/16

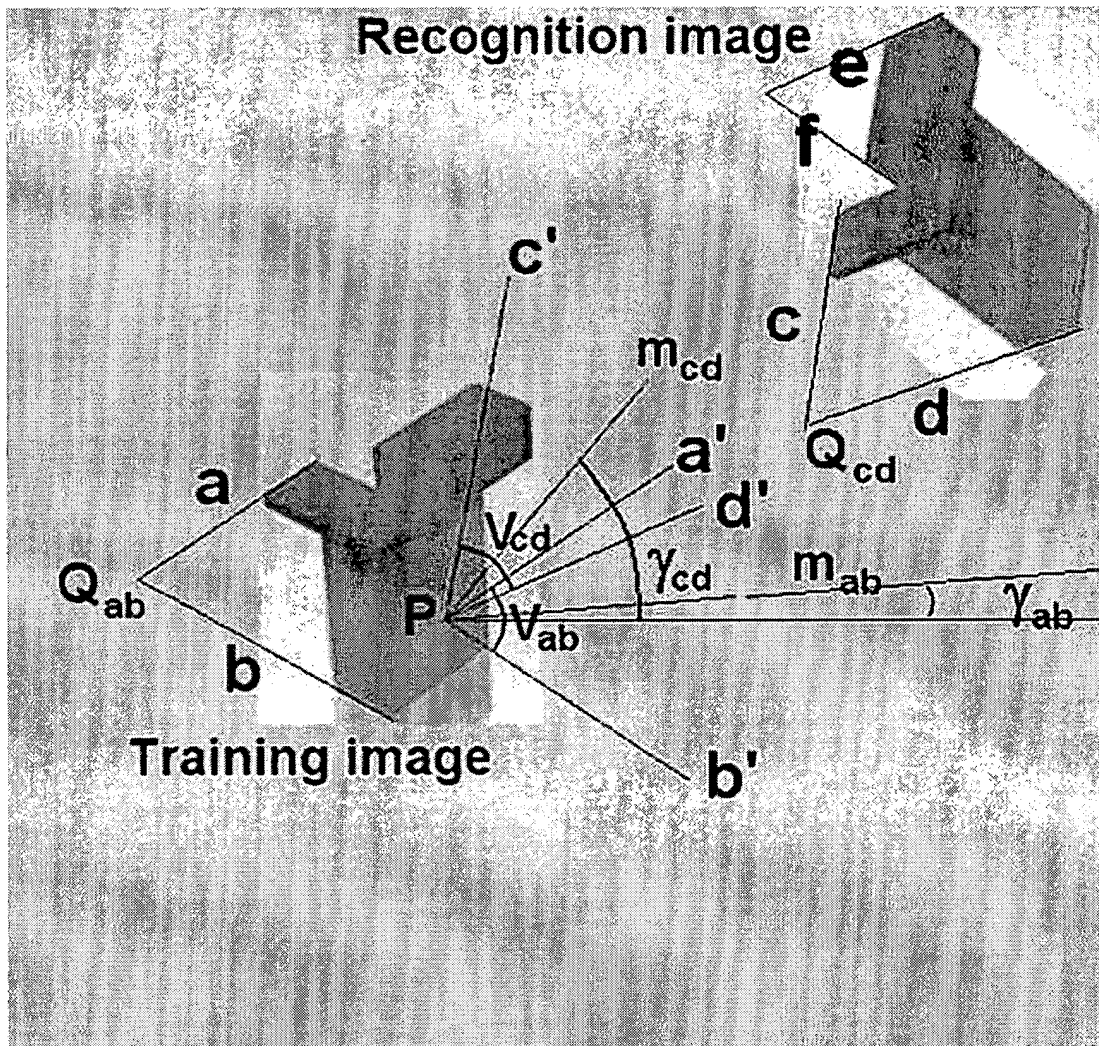


Fig. 10

10/16 Training flow chart

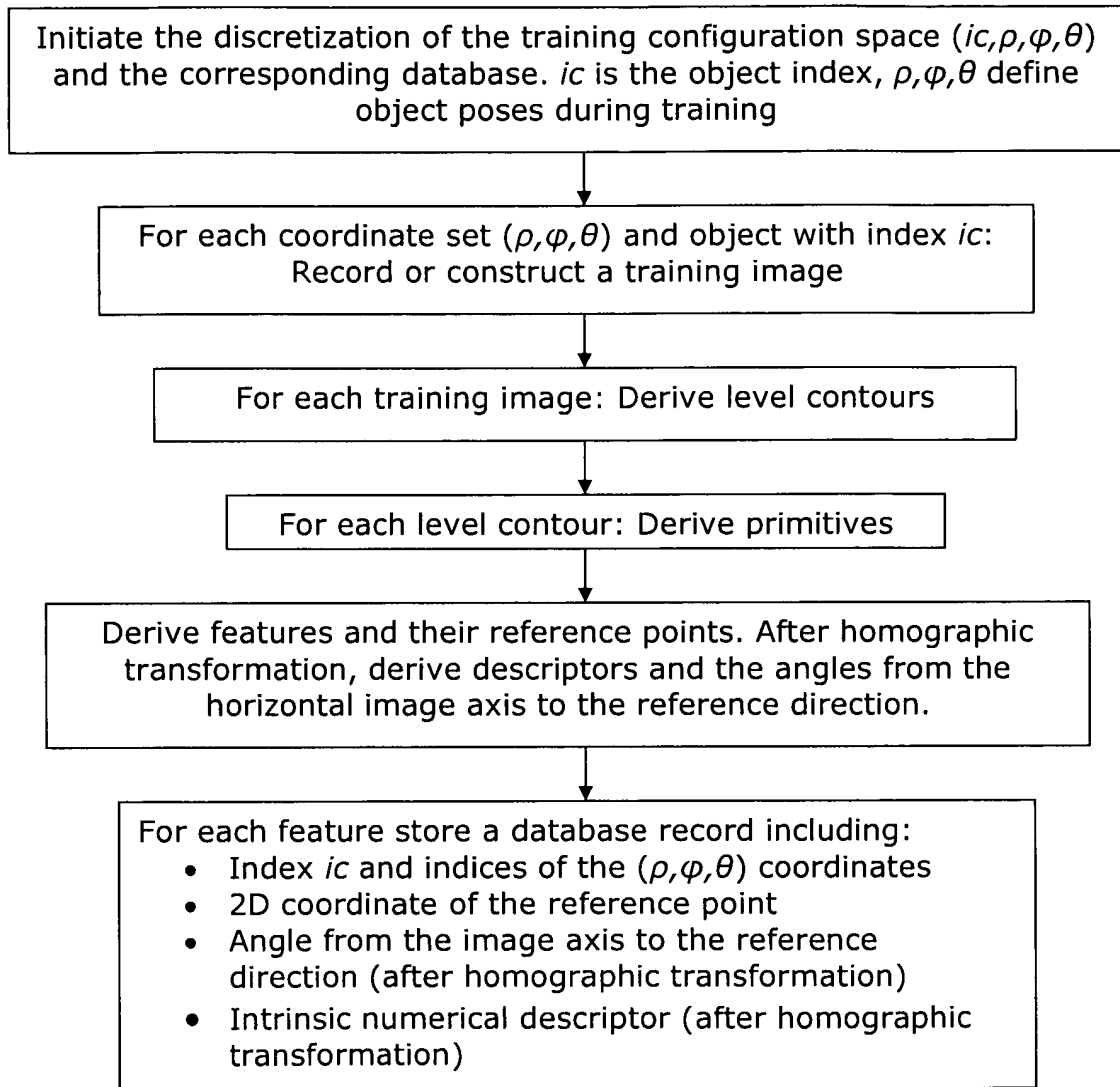
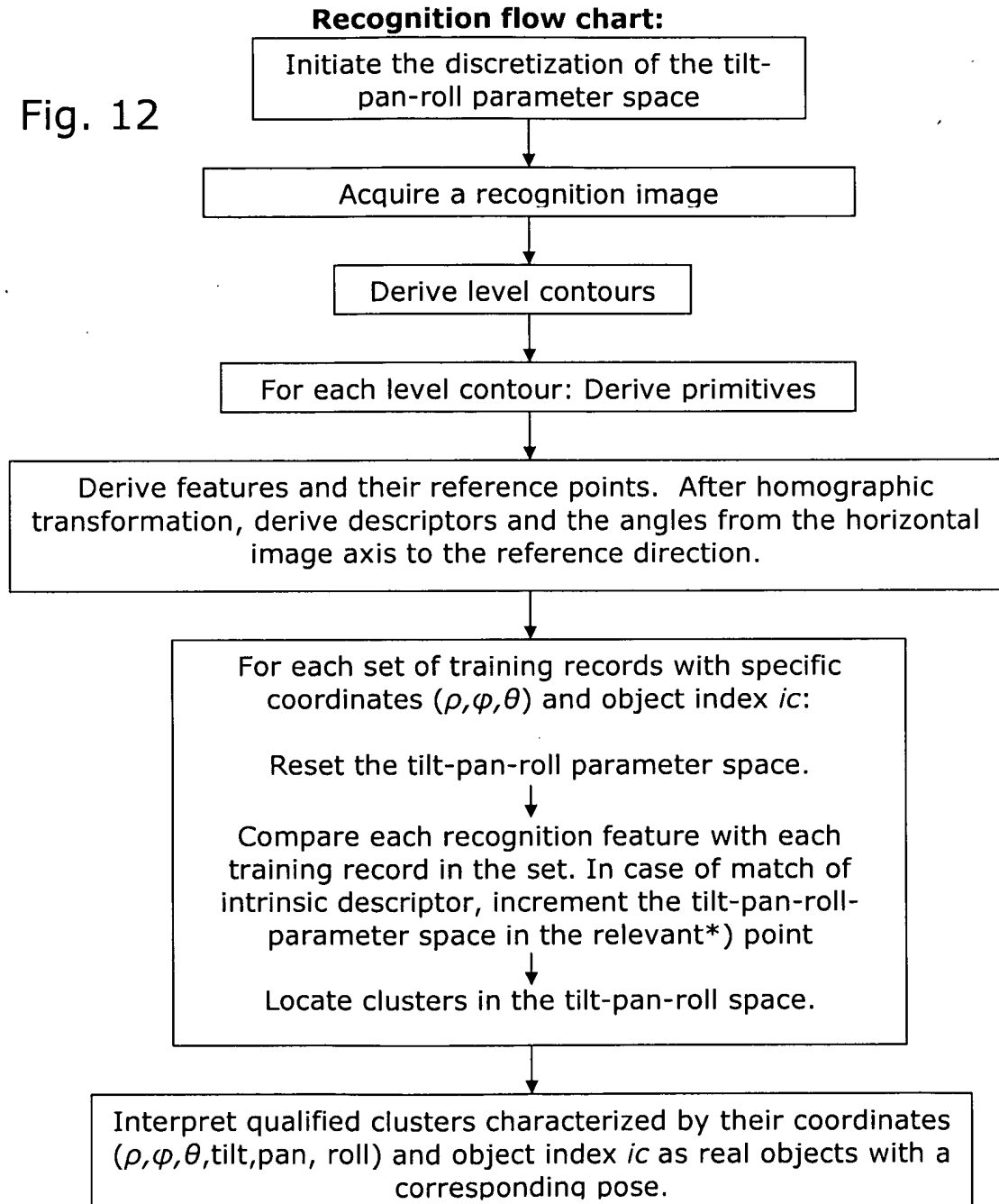


Fig. 11

Fig. 12



*) The (tilt, pan, roll) define the angular offset between the potential recognition pose and the actual training pose. This coordinate set is derived using the reference points and reference directions of both training and recognition features, see Appendix A

Fig. 13

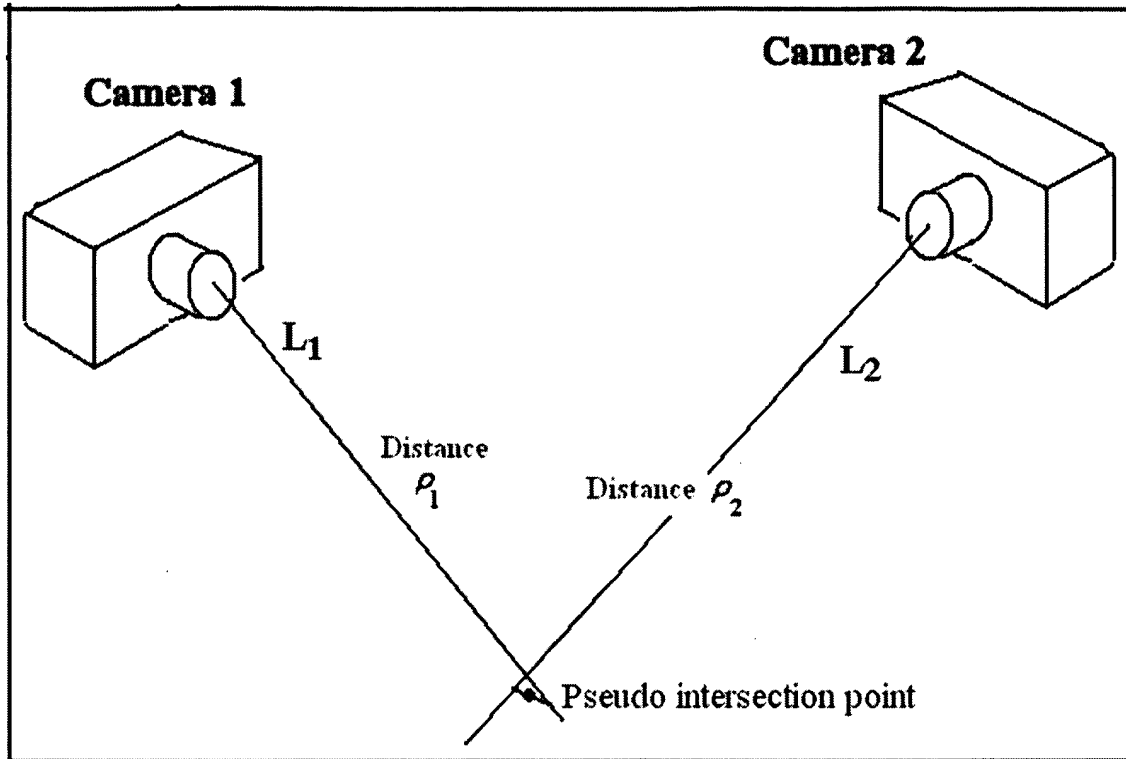
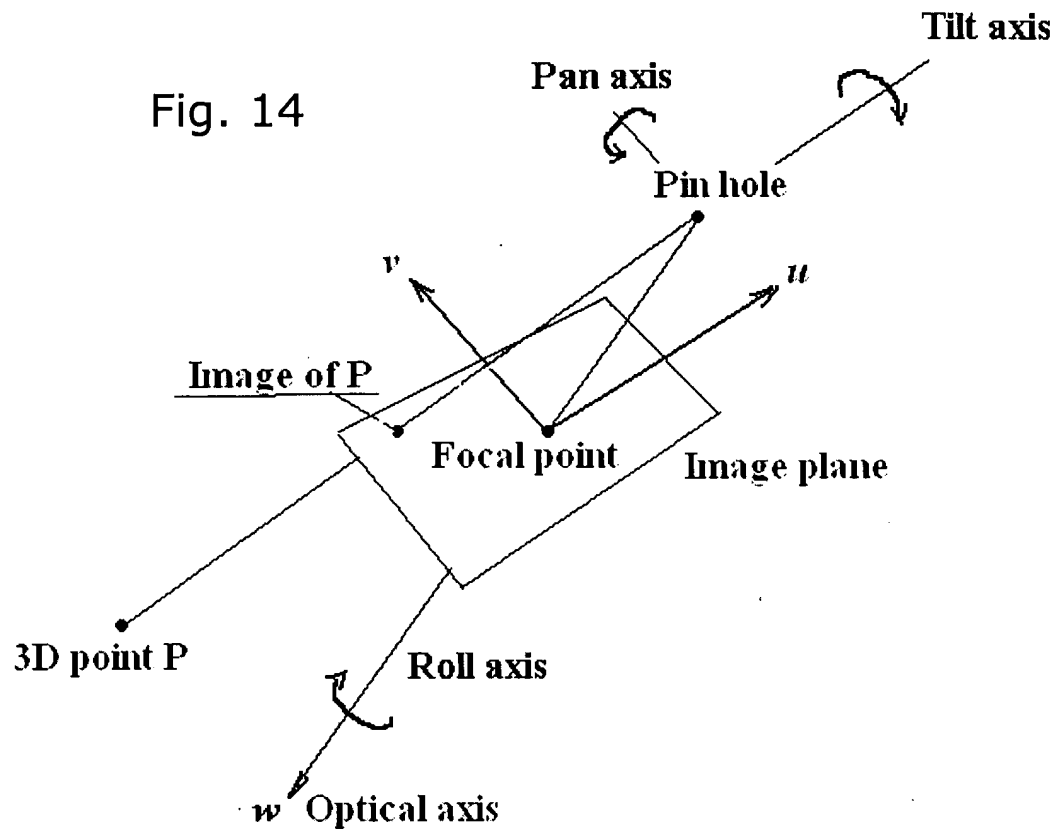


Fig. 14



14/16

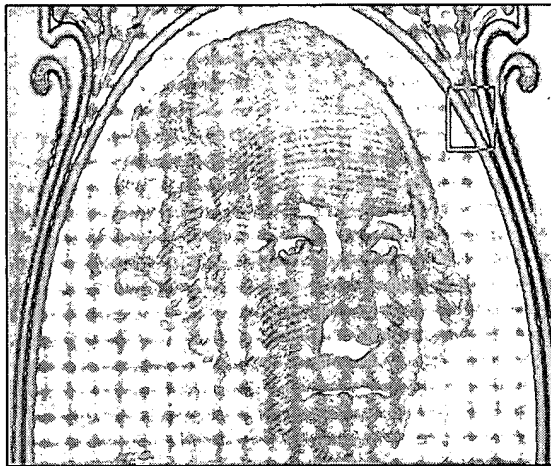


Fig. 15a

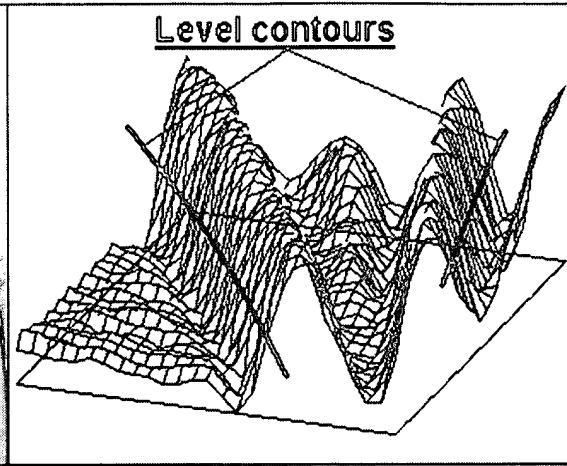


Fig. 15b

Fig. 15

15/16

Fig. 16

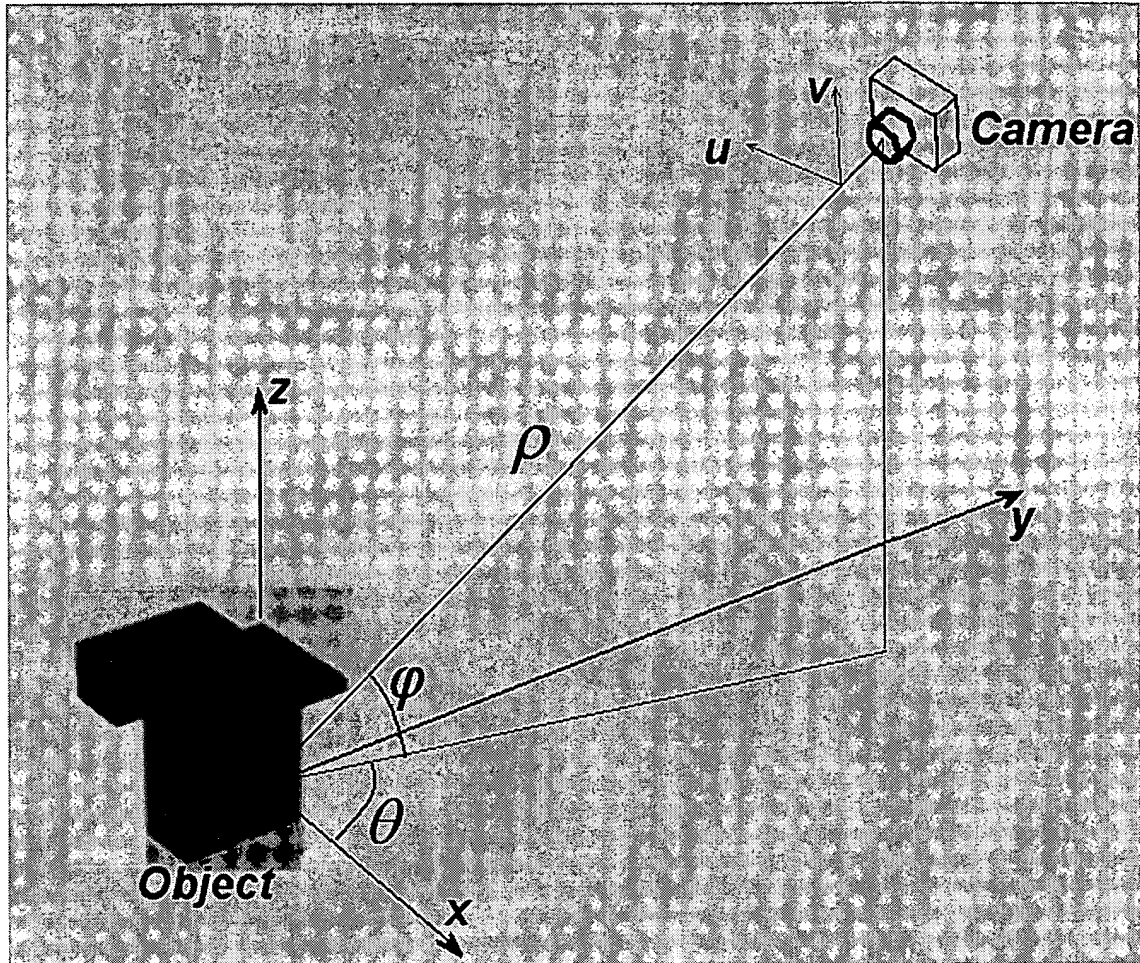


Fig. 17

	Intrinsic descriptors Λ			Extrinsic descriptors		
	ref.point	ref.point	ref. dir
Training image 1				u_Q	v_Q	γ
Training image 2						

Fig. 18

[illegible]